1. Record Nr. UNINA9910790735403321

Titolo	Churchmen and urban government in late Medieval Italy, c. 1200-c. 1450 / / edited by Frances Andrews with Maria Agata Pincelli [[electronic resource]]
Pubbl/distr/stampa	Cambridge : , : Cambridge University Press, , 2013
ISBN	1-107-70330-1 1-139-89372-6 1-107-62129-1 1-107-70405-7 1-107-36008-0 1-107-59880-X 1-107-69412-4 1-107-67108-6
Descrizione fisica	1 online resource (xvi, 411 pages) : digital, PDF file(s)
Disciplina	322/.109450902
Soggetti	Christianity and politics - Italy - History Italy Church history 476-1400 Italy Politics and government 1268-1559
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Title from publisher's bibliographic system (viewed on 05 Oct 2015).
Nota di bibliografia	Includes bibliographical references and index.
Nota di contenuto	part I. Urban case studies -- part II. Ecclesiastical perspectives -- part III. Comparisons beyond central and northern Italy.
Sommario/riassunto	Why, when so driven by the impetus for autonomy, did the city elites of thirteenth-century Italy turn to men bound to religious orders whose purpose and reach stretched far beyond the boundaries of their often disputed territories? Churchmen and Urban Government in Late Medieval Italy, c.1200-c.1450 brings together a team of international contributors to provide the first comparative response to this pivotal question. Presenting a series of urban cases and contexts, the book explores the secular-religious boundaries of the period and evaluates the role of the clergy in the administration and government of Italy's city-states. With an extensive introduction and epilogue, it exposes for

	consideration the beginnings of the phenomenon, the varying responses of churchmen, the reasons why practices changed and how politics and religious identity relate to each other. This important new study has significant implications for our understanding of power, negotiation, bureaucracy and religious identity.

2.

Record Nr.	UNINA9910962885403321
Autore	Bullo Francesco
Titolo	Distributed control of robotic networks : a mathematical approach to motion coordination algorithms / / Francesco Bullo, Jorge Cortes, Sonia Martinez
Pubbl/distr/stampa	Princeton, NJ, : Princeton University Press, 2009
ISBN	9786612458200 9786612935756 9781680158977 168015897X 9781282458208 1282458205 9781282935754 1282935755 9781400831470 1400831474 9780691141954 0691141959
Edizione	[Course Book]
Descrizione fisica	1 online resource (333 p.)
Collana	Princeton series in applied mathematics
Classificazione	SK 880
Altri autori (Persone)	CortesJorge <1974-> MartinezSonia <1974->
Disciplina	629.8/9246
Soggetti	Robotics Computer algorithms Robots - Control systems
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Description based upon print version of record.
Nota di bibliografia	Includes bibliographical references and index.

Nota di contenuto	Frontmatter -- Contents -- Preface -- Chapter One. An introduction to distributed algorithms -- Chapter Two. Geometric models and optimization -- Chapter Three. Robotic network models and complexity notions -- Chapter Four. Connectivity maintenance and rendezvous -- Chapter Five. Deployment -- Chapter Six. Boundary estimation and tracking -- Bibliography -- Algorithm Index -- Subject Index -- Symbol Index
Sommario/riassunto	This self-contained introduction to the distributed control of robotic networks offers a distinctive blend of computer science and control theory. The book presents a broad set of tools for understanding coordination algorithms, determining their correctness, and assessing their complexity; and it analyzes various cooperative strategies for tasks such as consensus, rendezvous, connectivity maintenance, deployment, and boundary estimation. The unifying theme is a formal model for robotic networks that explicitly incorporates their communication, sensing, control, and processing capabilities--a model that in turn leads to a common formal language to describe and analyze coordination algorithms. Written for first- and second-year graduate students in control and robotics, the book will also be useful to researchers in control theory, robotics, distributed algorithms, and automata theory. The book provides explanations of the basic concepts and main results, as well as numerous examples and exercises. Self-contained exposition of graph-theoretic concepts, distributed algorithms, and complexity measures for processor networks with fixed interconnection topology and for robotic networks with position-dependent interconnection topology Detailed treatment of averaging and consensus algorithms interpreted as linear iterations on synchronous networks Introduction of geometric notions such as partitions, proximity graphs, and multicenter functions Detailed treatment of motion coordination algorithms for deployment, rendezvous, connectivity maintenance, and boundary estimation